

## Claims

1. An industrial robot comprising a first member and a second member which rotate relatively at a joint portion thereof;

5 the first member including:

a mount portion where a positioning member is embedded and

a guide portion along which the positioning member slides in such a manner as to protrude; and

10 the second member including:

an abutment portion which is brought into abutment with the positioning member when the first and second members are made to rotate relatively.

15 2. An industrial robot comprising a first member and a second member which rotate relatively at a joint portion thereof;

the first member including:

a first mount portion where a first positioning member is embedded and

20 a first guide portion along which the first positioning member slides in such a manner as to protrude; and

the second member including:

25 a second mount portion where a second positioning member is embedded and

a second guide portion along which the second positioning member slides in such a manner as to protrude, whereby the first and second positioning members are brought into abutment with each other when the first member and the second member are made to rotate relatively.

3. An industrial robot as set forth in Claim 1 or 2, wherein the positioning member is held at a position where the positioning member does not protrude from the first member when performing a normal operation, whereas only when performing an origin adjustment, the positioning member is made to protrude.

4. An industrial robot as set forth in Claim 3, wherein the positioning member is brought into abutment at a mechanical origin position of the industrial robot.

5. An industrial robot as set forth in Claim 3, further comprising calculation means for bringing the positioning member into abutment at a position which is displaced from a mechanical origin position through a known angle determined in advance and calculating the mechanical origin position using the known angular displacement and the abutment position of the positioning member.

6. An industrial robot as set forth in Claim 3, wherein

the abutment of the positioning member is determined by monitoring a torque generated in the second member using a current to a driving motor for relatively rotating the second member.